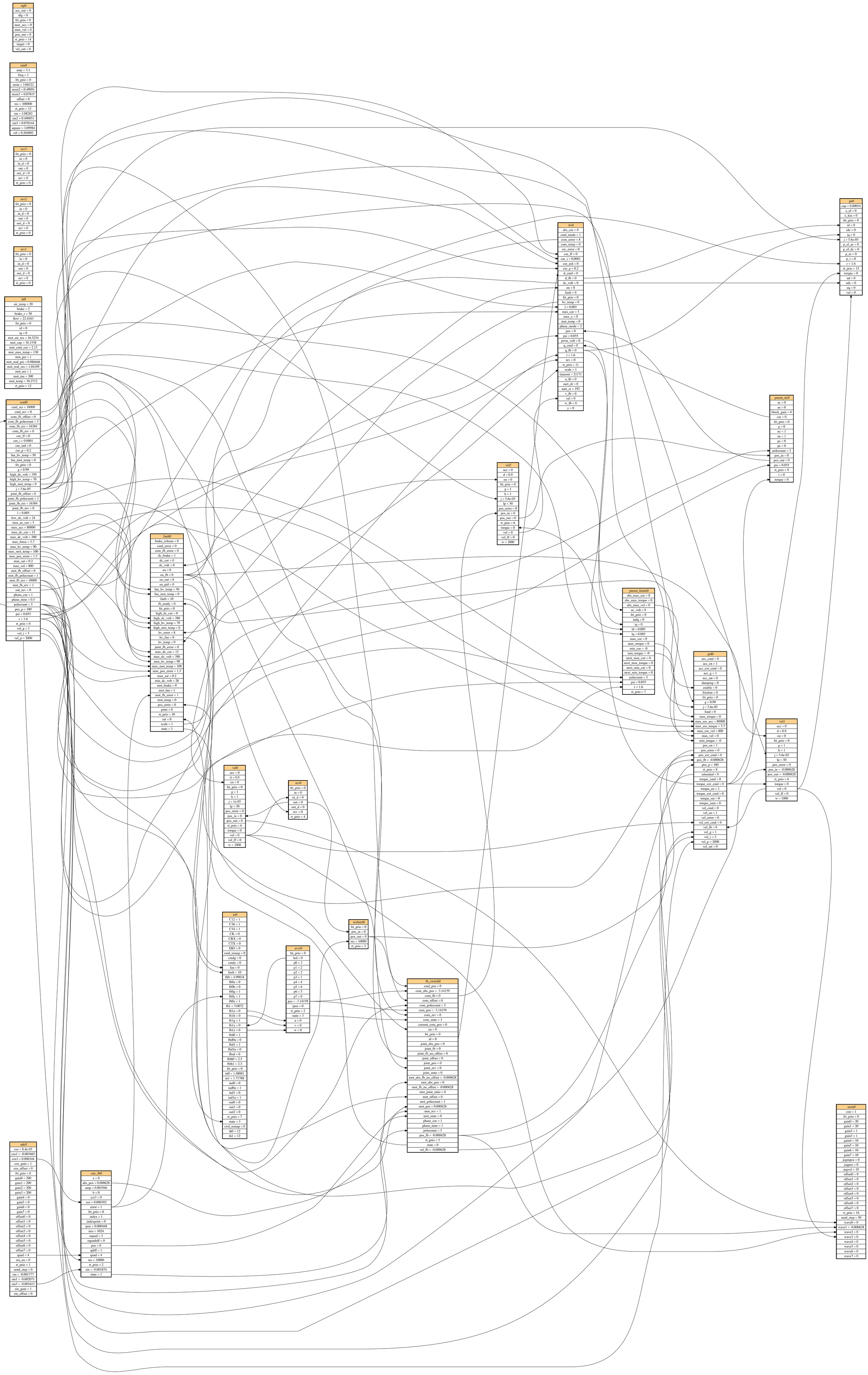
stp0
acc_out = 0
dtg = 0
frt_prio = 0
max_acc = 0
max_vel = 0
pos_out = 0
rt_prio = 14
target = 0
vel_out = 0
sim0
amp = 3.1
freq = 1
frt_prio = 0
msin = 3.08322
msin2 = 0.49091
msin3 = 0.07815
offset = 0
res = 100000
rt_prio = 13
sin = 3.08282
sin2 = 0.490851
sin3 = 0.078144
square = 3.09984
vel = 0.264882
rev3
frt_prio = 0
in = 0
in_d = 0
out = 0
out_d = 0
rev = 0
rt_prio = 0
rev2
frt_prio = 0
in = 0
in_d = 0
out = 0
out_d = 0
rev = 0
rt_prio = 0
rev1
frt_prio = 0
in = 0
in_d = 0
out = 0
out_d = 0
rev = 0
rt_prio = 0
iit0
air_temp = 20
brake = 2
brake_r = 50
flow = 22.4183
frt_prio = 0
id = 0
iq = 0
mot_air_res = 16.5254
mot_cap = 18.1538
mot_cont_cur = 2.15
mot_max_temp = 130
mot_psi = 1
mot_real_psi = 0.986646
mot_real_res = 1.04109
mot_res = 1
mot_tau = 300
mot_temp = 30.2712
rt_prio = 12
conf0
cmd_res = 10000
cmd_rev = 0
com_fb_offset = 0
com_fb_polecount = 5
com_fb_res = 16384
com_fb_rev = 0
cur_ff = 0
cur_i = 0.0001
cur_ind = 0
cur_p = 0.2
fan_hv_temp = 50
fan_mot_temp = 0
frt_prio = 0
g = 0.99
high_dc_volt = 350
high_hv_temp = 70
high_mot_temp = 0
j = 5.6e-05
joint_fb_offset = 0
joint_fb_polecount = 1
joint_fb_res = 16384
joint_fb_rev = 0
l = 0.005
low_dc_volt = 24
max_ac_cur = 5
max_acc = 80000
max_dc_cur = 15
max_dc_volt = 380
max_force = 5.7
max_hv_temp = 90
max_mot_temp = 100
max_pos_error = 1.5
max_sat = 0.2
max_vel = 800
mot_fb_offset = 0
mot_fb_polecount = 1
mot_fb_res = 10000
mot_fb_rev = 1
out_rev = 0
phase_cur = 1
phase_time = 0.5
polecount = 5
pos_p = 100
psi = 0.055
r = 1.6
rt_prio = 0
vel_g = 1
vel_i = 5
vel_p = 2000
hv0
abs_cur = 0
cmd_mode = 1
com_error = 8
core_temp = 0
crc_error = 0
cur_ff = 0
cur_i = 0.0001
cur_ind = 0
cur_p = 0.2
d_cmd = 0
d_fb = 0
dc_volt = 0
en = 0
fault = 0
frt_prio = 0
hv_temp = 0
l = 0.005
max_cur = 5
max_y = 0
mot_temp = 0
phase_mode = 2
pos = 0
psi = 0.055
pwm_volt = 0
q_cmd = 0
q_fb = 0
r = 1.6
rev = 0
rt_prio = 11
scale = 1
timeout = 21171
u_fb = 0
uart_dr = 0
uart_sr = 192
v_fb = 0
vel = 0
w_fb = 0
y = 0
ps0
cap = 0.00054
e_el = 0
e_kin = 0
frt_prio = 0
id = 0
idc = 0
iq = 0
j = 5.6e-05
p_el_ac = 0
p_el_dc = 0
p_m = 0
p_t = 0
r = 1.6
rt_prio = 15
torque = 0
ud = 0
udc = 0
uq = 0
vel = 0
pmsm_ttc0
ac = 0
ae = 0
block_gain = 0
cur = 0
frt_prio = 0
g = 0
nc = 1
ne = 1
pc = 0
pe = 0
polecount = 5
pos_in = 0
pos_out = 0
psi = 0.055
rt_prio = 9
t = 0
torque = 0
vel2
acc = 0
d = 0.9
en = 0
frt_prio = 0
g = 1
h = 1
j = 5.6e-05
lp = 50
pos_error = 0
pos_in = 0
pos_out = 0
rt_prio = 6
torque = 0
vel = 0
vel_ff = 0
w = 1000
fault0
brake_release = 0
cmd_error = 0
com_fb_error = 0
dc_brake = 1
dc_cur = 0
dc_volt = 0
en = 0
en_fb = 0
en_out = 0
en_pid = 0
fan_hv_temp = 50
fan_mot_temp = 0
fault = 10
fb_ready = 0
frt_prio = 0
high_dc_cur = 0
high_dc_volt = 380
high_hv_temp = 70
high_mot_temp = 0
hv_error = 8
hv_fan = 0
hv_temp = 0
joint_fb_error = 0
max_dc_cur = 15
max_dc_volt = 380
max_hv_temp = 90
max_mot_temp = 100
max_pos_error = 1.5
max_sat = 0.2
min_dc_volt = 20
mot_brake = 0
mot_fan = 1
mot_fb_error = 1
mot_temp = 0
pos_error = 0
print = 0
rt_prio = 10
sat = 0
scale = 1
state = 3
pmsm_limits0
abs_max_cur = 0
abs_max_torque = 0
abs_max_vel = 0
ac_volt = 0
frt_prio = 0
indq = 0
iq = 0
ld = 0.005
lq = 0.005
max_cur = 0
max_torque = 0
min_cur = -0
min_torque = -0
next_max_cur = 0
next_max_torque = 0
next_min_cur = 0
next_min_torque = 0
polecount = 5
psi = 0.055
r = 1.6
rt_prio = 7
pid0
acc_cmd = 0
acc_en = 1
acc_ext_cmd = 0
acc_g = 1
acc_sat = 0
damping = 0
enable = 0
friction = 0
frt_prio = 0
g = 0.99
j = 5.6e-05
load = 0
max_torque = 0
max_usr_acc = 80000
max_usr_torque = 5.7
max_usr_vel = 800
max_vel = 0
min_torque = -0
pos_en = 1
pos_error = 0
pos_ext_cmd = 0
pos_fb = -0.000628
pos_p = 100
rt_prio = 8
saturated = 0
torque_cmd = 0
torque_cor_cmd = 0
torque_en = 1
torque_ext_cmd = 0
torque_sat = 0
torque_sum = 0
vel_cmd = 0
vel_en = 1
vel_error = 0
vel_ext_cmd = 0
vel_fb = 0
vel_g = 1
vel_i = 5
vel_p = 2000
vel_sat = 0
vel1
acc = 0
d = 0.9
en = 0
frt_prio = 0
g = 1
h = 1
j = 5.6e-05
lp = 50
pos_error = 0
pos_in = -0.000628
pos_out = -0.000628
rt_prio = 6
torque = 0
vel = 0
vel_ff = 0
w = 1000
vel0
acc = 0
d = 0.9
en = 0
frt_prio = 0
g = 1
h = 1
j = 1e-05
lp = 50
pos_error = 0
pos_in = 0
pos_out = 0
rt_prio = 6
torque = 0
vel = 0
vel_ff = 0
w = 1000
rev0
frt_prio = 0
in = 0
in_d = 0
out = 0
out_d = 0
rev = 0
rt_prio = 4
io0
C12 = 1
C36 = 1
C54 = 1
CK = 0
CRX = 0
CTX = 0
DIO = 0
cmd_remap = 0
cmdg = 0
cmdy = 0
fan = 0
fault = 10
fb0 = 4.99834
fb0a = 0
fb0b = 0
fb0g = 1
fb0y = 1
fb0z = 1
fb1 = 5.0072
fb1a = 0
fb1b = 0
fb1g = 1
fb1y = 0
fb1z = 0
fbd0 = 1
fbd0n = 0
fbd1 = 1
fbd1n = 0
fbsd = 0
fbth0 = 2.5
fbth1 = 2.5
frt_prio = 0
in0 = 1.48081
in1 = 1.71768
ind0 = 0
ind0n = 1
ind1 = 0
ind1n = 1
out0 = 0
out1 = 0
out2 = 0
rt_prio = 7
state = 3
swd_remap = 0
th0 = 12
th1 = 12
uvw0
frt_prio = 0
led = 0
p0 = 3
p1 = 2
p2 = 2
p3 = 1
p4 = 4
p5 = 6
p6 = 5
p7 = 0
pos = -3.14159
rpos = 0
rt_prio = 2
state = 3
u = 0
v = 0
w = 0
reslimit0
frt_prio = 0
pos_in = 0
pos_out = 0
res = 10000
rt_prio = 3
fb_switch0
cmd_pos = 0
com_abs_pos = -3.14159
com_fb = 0
com_offset = 0
com_polecount = 5
com_pos = -3.14159
com_rev = 0
com_state = 3
current_com_pos = 0
en = 0
frt_prio = 0
id = 0
joint_abs_pos = 0
joint_fb = 0
joint_fb_no_offset = 0
joint_offset = 0
joint_pos = 0
joint_rev = 0
joint_state = 0
mot_abs_fb_no_offset = -0.000628
mot_abs_pos = 0
mot_fb_no_offset = -0.000628
mot_joint_ratio = 0
mot_offset = 0
mot_polecount = 1
mot_pos = 0.000628
mot_rev = 1
mot_state = 0
phase_cur = 1
phase_time = 1
polecount = 5
pos_fb = -0.000628
rt_prio = 5
state = 0
vel_fb = -0.000628
adc0
cos = 8.4e-05
cos1 = -0.003665
cos3 = 0.000344
cos_gain = 1
cos_offset = 0
frt_prio = 0
gain0 = 200
gain1 = 200
gain2 = 200
gain3 = 200
gain4 = 0
gain5 = 0
gain6 = 0
gain7 = 0
offset0 = 0
offset1 = 0
offset2 = 0
offset3 = 0
offset4 = 0
offset5 = 0
offset6 = 0
offset7 = 0
quad = 4
res_en = 0
rt_prio = 1
send_step = 0
sin = -0.001777
sin1 = -0.002071
sin3 = -0.001613
sin_gain = 1
sin_offset = 0
enc_fb0
a = 0
abs_pos = 0.000628
amp = 0.001946
b = 0
ccr3 = 0
cos = 0.000302
error = 1
frt_prio = 0
index = 1
indexprint = 0
ipos = 0.000448
ires = 1024
oquad = 3
oquadoff = 0
pos = 0
qdiff = 1
quad = 4
res = 10000
rt_prio = 2
sin = -0.001874
state = 1
term0
con = 1
frt_prio = 0
gain0 = 20
gain1 = 20
gain2 = 1
gain3 = 1
gain4 = 10
gain5 = 10
gain6 = 10
gain7 = 10
jogmpos = 0
jogpos = 0
jogvel = 10
offset0 = 0
offset1 = 0
offset2 = 0
offset3 = 0
offset4 = 0
offset5 = 0
offset6 = 0
offset7 = 0
rt_prio = 16
send_step = 50
wave0 = 0
wave1 = -0.000628
wave2 = 0
wave3 = 0
wave4 = 0
wave5 = 0
wave6 = 0
wave7 = 0